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What is claimed is:

1. Removing from a retinal image acquired by a fundus camera, image degradations arising from intraocular defects, comprising the steps of:

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- a.) digitizing said acquired image;
- b.) taking an FFT of said digitized image by rows and columns;
- c.) correlating said FFTs to obtain resultant row product vectors and column vectors;

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- finding the root equal to the respective numbers of rows and columns of the resultant row and column product vectors to obtain quotients;
- e.) subtracting from each of said quotients a minimum offset term to obtain the PSF spatial spectrum (MTF) of the eye;
- f.) dividing each row FFT and each column FFT by said MTF; and
- g.) taking the inverse FFT to yield a restored distortion-reduced image.

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- 2. The method of removing from an acquired image degradations arising from optical defects in inaccessible portions of the optical path, comprising the steps of
 - a.) digitizing said acquired image;
 - b.) scanning said acquired image along predetermined paths to obtain vectors of data;
 - c.) taking a discrete transform of said vectors of data;
 - d.) correlating said discrete transform of said vectors to obtain resultant product vectors;
 - e.) finding roots of the resultant product vectors for each of said predetermined paths;

f.) subtracting from each of said roots a minimum offset term to obtain a point spread function spatial spectrum (MTF);

- g.) dividing each discrete transform of said vectors by said MTF; and
- h.) taking the inverse discrete transform to yield a restored distortion-reduced image.

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3. The method of claim 2 wherein said acquired image is a retinal image acquired by a fundus camera.

- 4. The method of claim 3 wherein at least one of said predetermined paths
 5 traverses a predetermined feature of said retinal image.
 - 5. The method of claim 3 wherein said discrete transform is a fast Fourier transform.
- 10 6. The method of claim 4 wherein said predetermined paths are row and column paths of said image.
 - 7. The method of claim 5 wherein there are N of said predetermined paths and said root is the Nth root of said product vectors.

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